In the claims:

Please amend the claims as follows:

1-20 (canceled)

21. (new) An industrial robot, comprising:

at least one linkage device comprising pull rods; and

a multi-joint system operatively connected to the linkage device, the multi-joint system comprising a plurality of three-axle ball and socket joints, each joint comprising a joint ball and a joint socket, the joint socket enclosing the joint ball with a space that comprises approximately one-half the ball or less, the joint socket further comprising a housing and at least one removable polymeric annular bearing member arranged in the housing, the housing comprising a surface against which a side surface of the at least one bearing member abuts, the surface comprising a plurality of friction-increasing grooves extending in a longitudinal direction of the surface, the grooves engaging and deforming the side surface of the at least one bearing member and being operative to increase friction between the at least one bearing member and the housing to rotationally immobilize the at least one bearing member in the housing.

22. (new) The industrial robot according to claim 21, wherein the industrial robot comprises a delta robot.

23. (new) The industrial robot according to claim 21, wherein the grooves are aligned at

an angle with respect to a longitudinal axis of the bearing member.

24. (new) The industrial robot according to claim 21, wherein the grooves comprise pointed tops.

25. (new) The industrial robot according to claim 21, wherein the side surface of the at least one bearing member comprises a plurality of grooves extending in a longitudinal direction of the side surface and compatible with the grooves in the housing.

26. (new) The industrial robot according to claim 21, wherein the grooves penetrate and permanently deform the bearing member.

27. (new) The industrial robot according to claim 21, wherein the housing and the bearing member each have a socket shape, wherein a spring force holds the ball and socket joint together and fixes the bearing member in place.

28. (new) The industrial robot according to claim 21, wherein the at least one bearing member is pressed to fit tightly in the housing.

29. (new) A method for forming an industrial robot, the method comprising:

providing at least one linkage device comprising pull rods;

providing a multi-joint system comprising a plurality of three-axle ball and socket joints, each joint comprising a joint ball and a joint socket;

providing the joint socket enclosing the joint ball with a space that comprises approximately one-half the ball or less;

providing the joint socket with a housing a side surface comprising a plurality of friction-increasing grooves extending in a longitudinal direction of the surface; and

arranging at least one removable polymeric annular bearing member in the housing, such that a side surface of the at least one bearing member abuts against the side surface of the housing and the grooves engage and deform the side surface of the at least one bearing member and increase friction between the at least one bearing member and the housing to rotationally immobilize the at least one bearing member in the housing.

30. (new) The method according to claim 29, wherein the method fixes a location of the bearing member in the robot.

31. (new) The method according to claim 29, wherein the industrial robot comprises a delta robot.

32. (new) The method according to claim 29, wherein the grooves are aligned at an angle with respect to a longitudinal axis of the bearing member.

33. (new) The method according to claim 29, wherein the grooves comprise pointed tops.

34. (new) The method according to claim 29, wherein the side surface of the at least one

bearing member comprises a plurality of grooves extending in a longitudinal direction of the side surface and compatible with the grooves in the housing.

35. (new) The method according to claim 29, wherein the grooves penetrate and permanently deform the bearing member.

36. (new) The method according to claim 29, wherein the housing and the bearing member each have a socket shape, wherein a spring force holds the ball and socket joint together and fixes the bearing member in place.

37. (new) The method according to claim 29, wherein the at least one bearing member is pressed to fit tightly in the housing.